Robotics and Automation		Semester	IV
Course Code	**BAG405D**	CIE Marks	50
Teaching Hours/Week (L: T:P: S)	3:0:0:0	SEE Marks	50
Total Hours of Pedagogy	40	Total Marks	100
Credits	03	Exam Hours	3
Examination nature (SEE)	Theory		

Course objectives:

The course will enable the students to

- Awareness about renewable Energy Sources and technologies.
- Adequate inputs on a variety of issues in harnessing renewable Energy.
- Recognize current and possible future role of renewable energy sources.

Teaching-Learning Process (General Instructions)

These are sample Strategies, which teachers can use to accelerate the attainment of the various course outcomes.

1. Adopt different type of teaching methods to develop the outcomes through Power-Point Presentation and Video demonstration or Simulations.
2. Chalk and Talk method for Problem Solving.
3. Arrange visits to show the live working models other than laboratory topics.
4. Adopt collaborative (Group Learning) Learning in the class.
5. Conduct Laboratory Demonstrations and Practical Experiments to enhance experiential skills.

Module-1

Definitions- Robots, Robotics; Types of Robots- Manipulators, Mobile Robots-wheeled & Legged Robots, Aerial Robots; Anatomy of a robotic manipulator-links, joints, actuators, sensors, controller; open kinematic vs closed kinematic chain; degrees of freedom; Robot configurations-PPP, RPP, RRP, RRR; features of SCARA, PUMA Robots; Classification of robots based on motion control methods and drive technologies; 3R concurrent wrist; Classification of End effectors - mechanical grippers, special tools, Magnetic grippers, Vacuum grippers, adhesive grippers, Active and passive grippers, selection and design considerations of grippers in robot.

Module-2

Robot Kinematics Direct Kinematics- Rotations-Fundamental and composite Rotations, Homogeneous coordinates, Translations and rotations, Composite homogeneous transformations, Screw transformations, Kinematic parameters, The Denavit-Hartenberg (D-H) representation, The arm equation, direct kinematics problems (upto 3DOF) Inverse kinematics- general properties of solutions, Problems (upto 3DOF) Inverse kinematics of 3DOF manipulator with concurrent wrist (demo/assignment only) Tool configuration Jacobian, relation between joint and end effector velocities.

Module-3

Trajectory planning Tasks Path planning Trajectory Planning. Joint space trajectory planning- cubic polynomial, linear trajectory with parabolic blends, trajectory planning with via points; Cartesian space planning, Point to point vs continuous path planning. Obstacle avoidance methods- Artificial Potential field, A* algorithms.

Module-4

Manipulator Dynamics Lagrange's formulation – Kinetic Energy expression, velocity Jacobian and Potential Energy expression, Generalised force, Euler-Lagrange equation, Dynamic model of planar and spatial serial robots upto 2 DOF, modelling including motor and gearbox.

Robot Control - The control problem, Single axis PID control-its disadvantages, PD gravity control, computed torque control. Simulation of simple robot-control system-Matlab programming for control of robots(demonstration/assignment only)

Module-5

Industrial Applications - Material handling, welding, Spray painting, Machining. Case study for robotic applications including robot selection considerations for a typical industrial ROBOTICS & AUTOMATION application- number of axes, work volume, capacity & speed, stroke &reach, Repeatability, Precision and Accuracy, Operating environment. forge – the robotic configuration for pick and place robot, spot welding robot in a car manufacturing industry, peg in hole assembly. Applications in the medical, mining, space, defence, security, domestic, entertainment.

Course outcome (Course Skill Set)

At the end of the course, the student will be able to :
1. Familiarise with anatomy, specifications and types of Robots
2. Obtain forward and inverse kinematic models of robotic manipulators
3. Plan trajectories in joint space & Cartesian space and avoid obstacles while robots are in motion
4. Develop dynamic model and design the controller for robotic manipulators
5. Choose appropriate Robotic configuration and list the technical specifications for robots used in different applications
6. Familiarise with different types of mobile robots, kinematic models, motion control and sensors for mobile robots

Assessment Details (both CIE and SEE)

The weightage of Continuous Internal Evaluation (CIE) is 50% and for Semester End Exam (SEE) is 50%. The minimum passing mark for the CIE is 40% of the maximum marks (20 marks out of 50) and for the SEE minimum passing mark is 35% of the maximum marks (18 out of 50 marks). A student shall be deemed to have satisfied the academic requirements and earned the credits allotted to each subject/ course if the student secures a minimum of 40% (40 marks out of 100) in the sum total of the CIE (Continuous Internal Evaluation) and SEE (Semester End Examination) taken together.

Continuous Internal Evaluation:
- For the Assignment component of the CIE, there are 25 marks and for the Internal Assessment Test component, there are 25 marks.
- The first test will be administered after 40-50% of the syllabus has been covered, and the second test will be administered after 85-90% of the syllabus has been covered
- Any two assignment methods mentioned in the 22OB2.4, if an assignment is project-based then only one assignment for the course shall be planned. The teacher should not conduct two assignments at the end of the semester if two assignments are planned.
- For the course, CIE marks will be based on a scaled-down sum of two tests and other methods of assessment.

Internal Assessment Test question paper is designed to attain the different levels of Bloom's taxonomy as per the outcome defined for the course.

Semester-End Examination:

Theory SEE will be conducted by University as per the scheduled timetable, with common question papers for the course **(duration 03 hours).**

- The question paper will have ten questions. Each question is set for 20 marks. .
- There will be 2 questions from each module. Each of the two questions under a module (with a maximum of 3 sub-questions), **should have a mix of topics** under that module.
- The students have to answer 5 full questions, selecting one full question from each module.

Marks scored shall be proportionally reduced to 50 marks

Suggested Learning Resources:

Books

1. Robert. J. Schilling , "Fundamentals of robotics – Analysis and control", Prentice Hall of India 1996.
2. Introduction to Robotics (Mechanics and control), John. J. Craig, Pearson Education Asia 2002.
3. Introduction to Robotics by S K Saha, Mc Graw Hill Education
4. R K Mittal and I J Nagrath, "Robotics and Control", Tata McGraw Hill, New Delhi,2003.
5. Ashitava Ghosal, "Robotics-Fundamental concepts and analysis", Oxford University press.
6. Robotics Technology and Flexible Automation, Second Edition, S. R. Deb
7. Introduction to Autonomous Mobile Robots, Siegwart, Roland, Cambridge, Mass. : MIT Press, 2nd ed.

Additional References:

1. Sicilliano, Khatib , "Handbook of Robotics", Springer
2. John J. Craig, Introduction to Robotics – Mechanics and Control
3. Kevin M. Lynch, Frank C. Park, Modern Robotics Mechanics, Planning and Control

Activity Based Learning (Suggested Activities in Class)/ Practical Based learning

- Quizzes
- Assignments
- Seminars

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